**Amendment to the Claims:**

This listing of the claims will replace all prior versions, and listings, of claims in the application.

**Listing of the Claims:**

1. (currently amended) A robotic surgical tool comprising:

a distal member configured to support an end effector; [[and]]

first and second components constrained to move in tandem and in opposite directions generally in parallel to an axial line and rotatably coupled to the distal member so that an advancement of the first component with a corresponding retraction of the second component causes the distal member to face a first articulated direction defining a first angle with respect to the axial line, and an advancement of the second component with a corresponding retraction of the first component causes the distal member to face a second articulated direction defining a second angle with respect to the axial line; and

third and fourth components constrained to move in tandem and in opposite directions generally in parallel to the axial line, and rotatably coupled to the distal member so that an advancement of the third component with a corresponding retraction of the fourth component causes the distal member to face a third articulated direction defining a third angle with respect to the axial line.

2. (previously presented) The robotic surgical tool as in claim 1, wherein the first angle is within a range approximately between zero and 30 degrees.

3. (previously presented) The robotic surgical tool as in claim 1, wherein the first angle is within a range approximately between zero and 60 degrees.

4. (previously presented) The robotic surgical tool as in claim 1, wherein the first angle is within a range approximately between zero and 70 degrees.

Claims 5-8 (canceled).

9. (currently amended) The robotic surgical tool as in claim 1[[8]], wherein intersections of the first, second, third, and fourth components through a plane orthogonal to the axial line define four corners of a square.

Claims 10-11 (canceled).

12. (previously presented) The robotic surgical tool as in claim 1, further comprising a tool base including a mechanism to advance and retract the first component.

13. (previously presented) The robotic surgical tool as in claim 12, wherein the mechanism includes a first rotational actuation member to which the first component is coupled so that rotation of the first rotational actuation member in a first rotary direction advances the first component and rotation of the first rotational actuation member in an opposite rotary direction retracts the first component.

14. (previously presented) The robotic surgical tool as in claim 13, wherein second component is coupled to the first rotational actuation member so that rotation of the first rotational actuation member in the first rotary direction retracts the second component and rotation of the first rotational actuation member in the second rotary direction advances the second component.

15. (previously presented) The robotic surgical tool as in claim 14, wherein rotation of the first rotational actuation member in the first rotary direction simultaneously advances the first component and retracts the second component by the same amount.

Claim 16 (canceled).

17. (previously presented) The robotic surgical tool as in claim 15, wherein the tool base further comprises a roll actuation mechanism coupled to the first

component and the second component so that actuation of the roll actuation mechanism causes the first component and the second component to rotate around the axial line.

18. (previously presented) The robotic surgical tool as in claim 13, wherein the tool base further includes means for actuating the end effector.

19. (previously presented) The robotic surgical tool as in claim 18, wherein the end effector comprises one of a group including grasping jaws, DeBakey forceps, microforceps, Potts scissors, a clip applier, a scalpel or an electrocautery probe.

20. (currently amended) A method of configuring a robotic surgical tool comprising: constraining first and second components to move in tandem and in opposite directions generally in parallel to an axial line so that movement of the first component in a first direction with corresponding movement of the second component in an opposite direction causes a distal member supporting an end effector to be oriented at a first angle with respect to the axial line, wherein the constraining of the first and second components to move in tandem and in opposite directions comprises providing a first rotational actuation member to which the first and second components are coupled on opposing sides so as to cause the first component to move in the first direction and the second component to move in an opposite direction when rotated in a first rotary direction.

Claims 21-24 (canceled).

25. (currently amended) The method as in claim 20[[22]], further comprising: constraining third and fourth components to move in tandem and in opposite directions generally in parallel to the axial line so that movement of the third component in the first direction with corresponding movement of the fourth component in the opposite direction causes the distal member to be oriented at a second angle with respect to the axial line.

26. (previously presented) The method as in claim 25, wherein the constraining of the third and fourth components to move in tandem and in opposite

directions comprises providing a second rotational actuation member to which the third and fourth components are coupled on opposing sides so as to cause the third component to move in the first direction and the fourth component to move in the opposite direction when rotated in the first rotary direction.

27. (previously presented) The method as in claim 26, further comprising providing a roll actuation member to which the first, second, third, and fourth components are coupled so as to cause the first, second, third, and fourth components to rotate around the axial line so that the end effector is rotated about the axial line when the roll actuation member is actuated.

Claims 28-29 (canceled).